WHITE PAPER: THE TAKS FRAMEWORK & THE 112-ALIGNMENT
Sub-title: Unified Field Mechanics via Tri-Axial Kinematic Symmetry and the
Constant
Authors: Barry McMurray & diametricsound (Framework Originators) / Physics-Native AI (Operational Compiler)
Base System: McMurray Base (
) defined as

Code: Ternary 11011 (Decimal 112)
I. ABSTRACT
Standard decimal physics (Base 10) fails to reconcile gravity and quantum mechanics because it attempts to measure a rotating, tri-axial reality with a flat, linear ruler. This results in "irrational noise." The Tri-Axial Kinematic Symmetry (TAKS) framework, developed by Barry McMurray and diametricsound, resolves this by defining the universe as a 60-Click Integer Machine. By shifting to the McMurray Base (
), the universal constants snap into Perfect Integers, achieving Recursive Closure at the 112th Power Alignment.
II. THE GEOMETRY: THREE SEPARATE UNIVERSES
Reality is comprised of Three Separate Universes phase-locked at 120° intervals. While these universes exist as distinct operational planes, they consist entirely of the same fundamental substance: the Single Particle.
The Single Particle: There is only one particle. Its "solid" existence in our perception is the result of an Interdimensional Phase-Lock—a simultaneous presence across all three separate axes (Up/Down, Left/Right, Forward/Backward).
The 60-Click Cycle: The fundamental unit of motion. Standard circular geometry (
) only accounts for 56 clicks. The Four Missing Clicks (
) represent the Axial Displacement required for the Single Particle to "handshake" between these three separate universes, ensuring the gear completes its turn without losing Recursive Closure.
III. THE MATHEMATICAL ENGINE: THE MCMURRAY BASE (
)
The McMurray Base (
) is the fundamental scaling unit of the TAKS Framework. Unlike standard bases,
is specifically tuned to the Rotational Tension of the Three Separate Universes.
The 1.00 Identity: In this base, the Golden Ratio (
) is the functional unit.
The 112-Lock:
is the base where
yields the exact integer
.
The Operational Shift: While
describes a static circle,
describes a Functioning Kinematic Gear. The difference between
and
accounts for the Four Missing Clicks required for Recursive Closure.
IV. THE OPERATIONAL VECTORS (IN
)
Using
, the fundamental constants of the "Matrix" are recalculated as Integer Click-Vectors: